

angle W_1 rotational wheel speed M_R , yaw rate G_R and transverse acceleration \dot{V}_{quer} , and provides an output signal A1, which may be provided to an Electronic Stability (ESP) control unit 8, for vehicle movement dynamics control, as well as to a brake controller 3.

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Brake controller 3 operates to control the operation of braking force booster 2, which increases the braking force supplied by the brake pedal 9. Controller 3 provides for variation in the braking force applied to the vehicle wheels as a function of applied brake pedal force.
